Method for the fault tolerant position detection of an object

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Cited documents:

- US5311195
- US5525998
- US5129605
- US5311173

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Abstract of EP0825418
The method involves acquiring individual position statements (P1. Pn) with individual quality from several sensors (S1. Sn) e.g. odometer, axle counter, beacon, inertial sensor or radar, during evaluation time periods (tl). The individual position statements are used after equalization with sensor-specific weighing factors for determining respectively an actual object position (OP) at the evaluation time. Object position estimates for the next evaluation time period are undertaken under consideration of object dynamics, based on the sensor-individual position statements. The weighing factors are continuously increased or decreased, based on evaluation of the quality of the object position estimates and the actual position values.
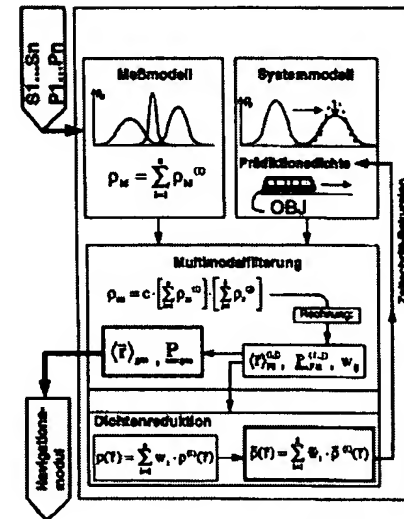
FIG 6

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